

Computer System 82

Figure 1

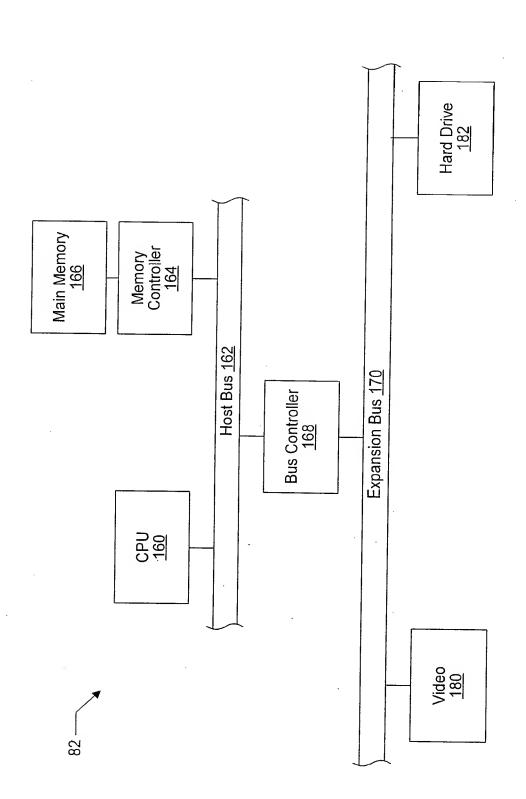
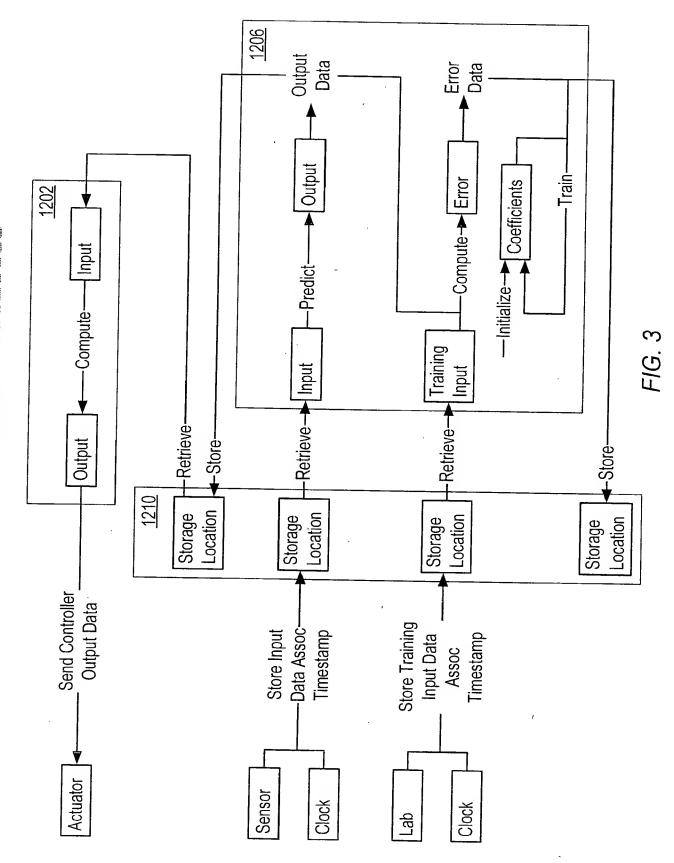


Figure 2



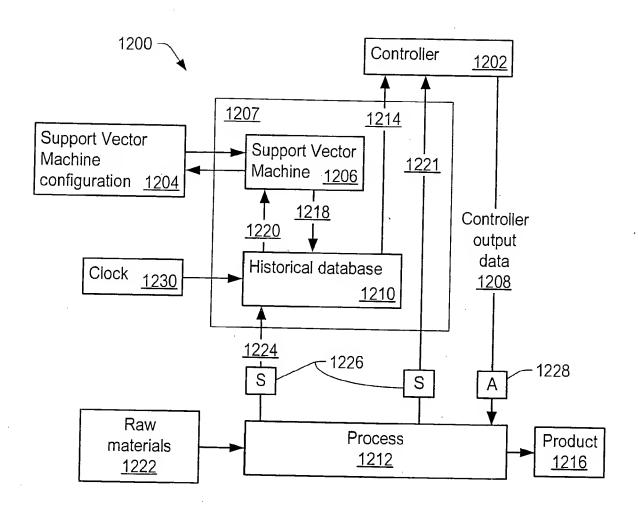


FIG. 4

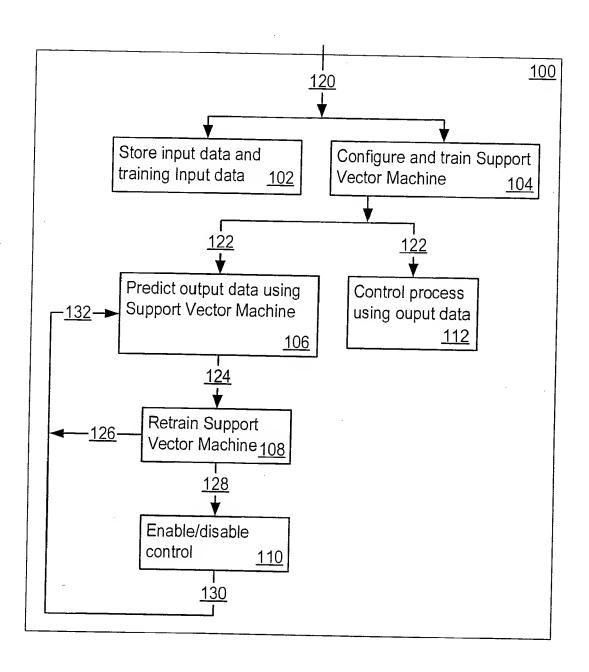


FIG. 5

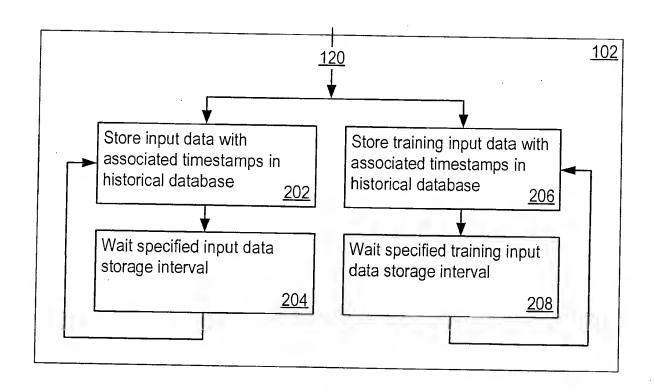


FIG. 6

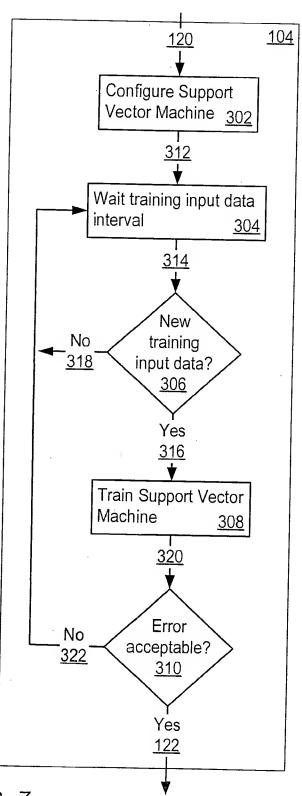
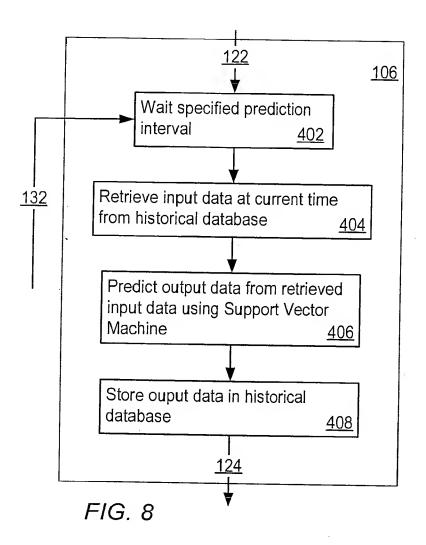


FIG. 7



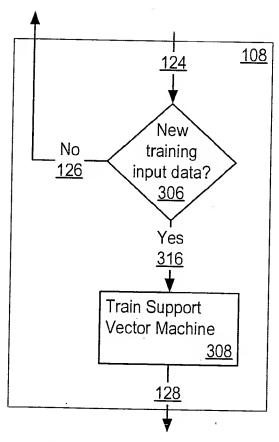


FIG. 9

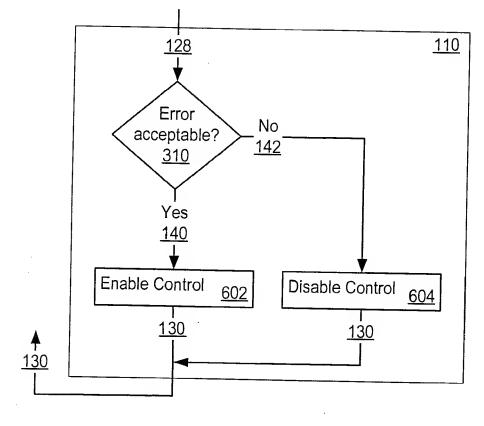


FIG. 10

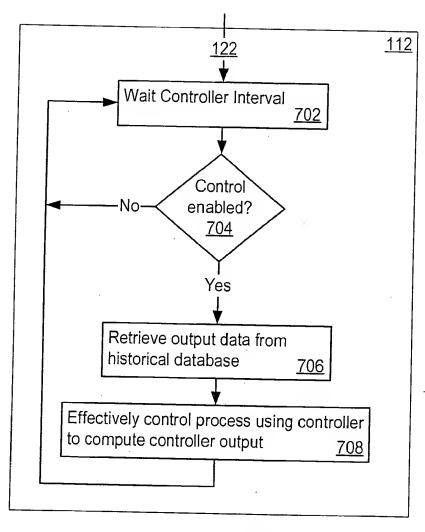


FIG. 11

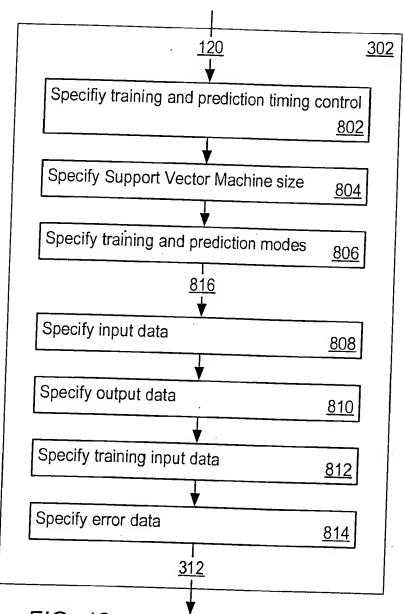


FIG. 12

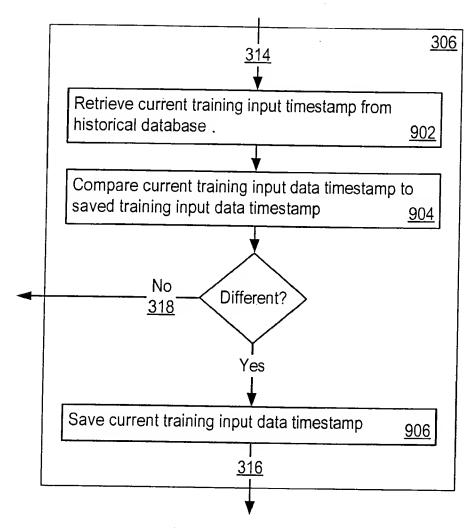


FIG. 13

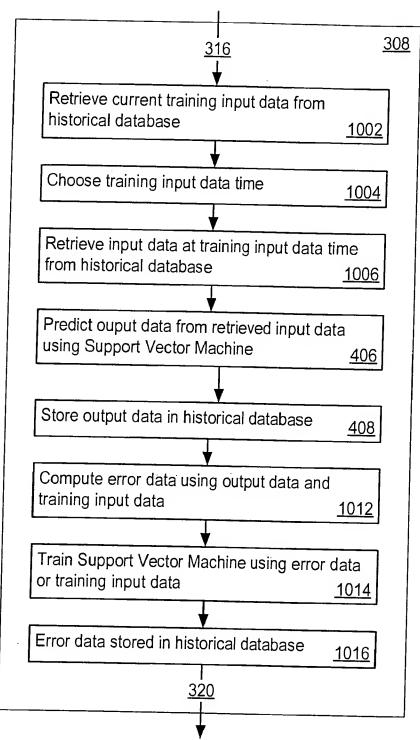
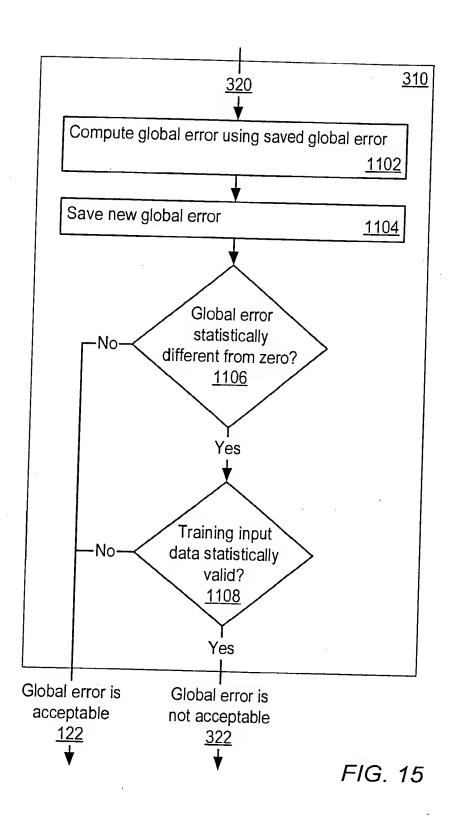


FIG. 14



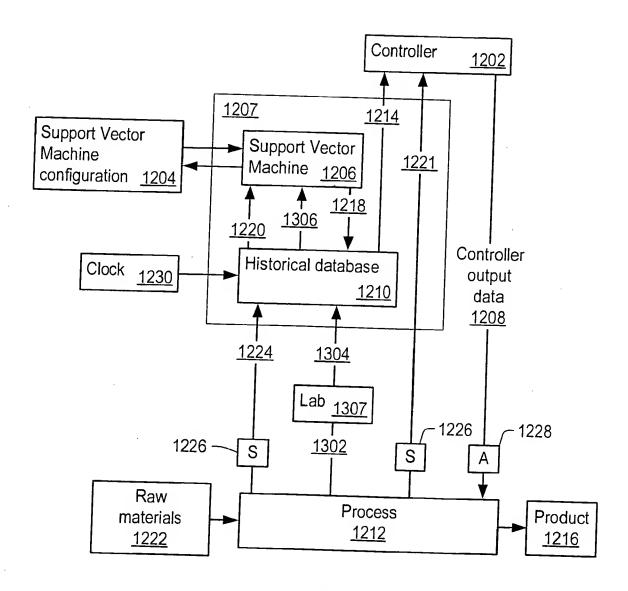


FIG. 16

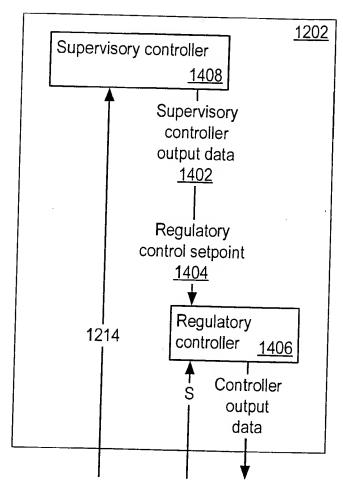
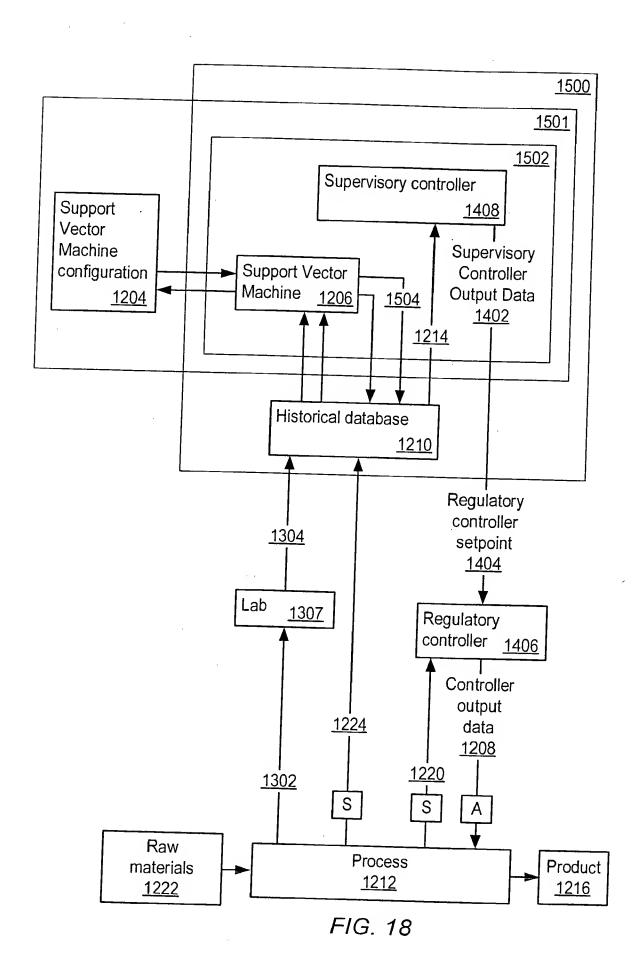


FIG. 17



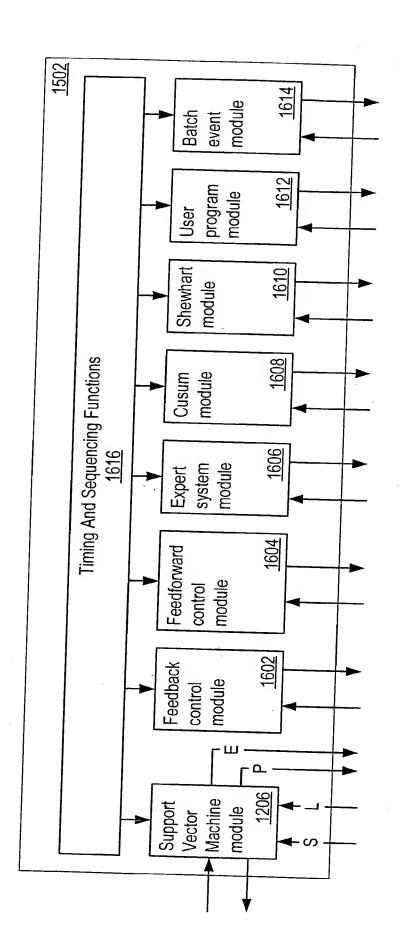


FIG. 19

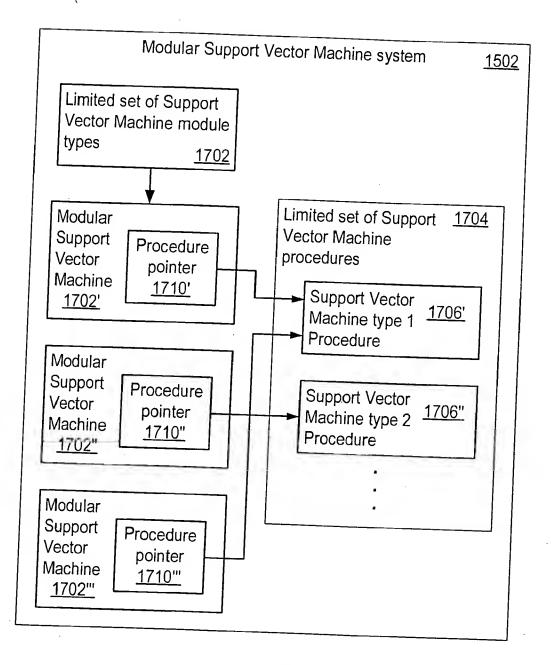


FIG. 20

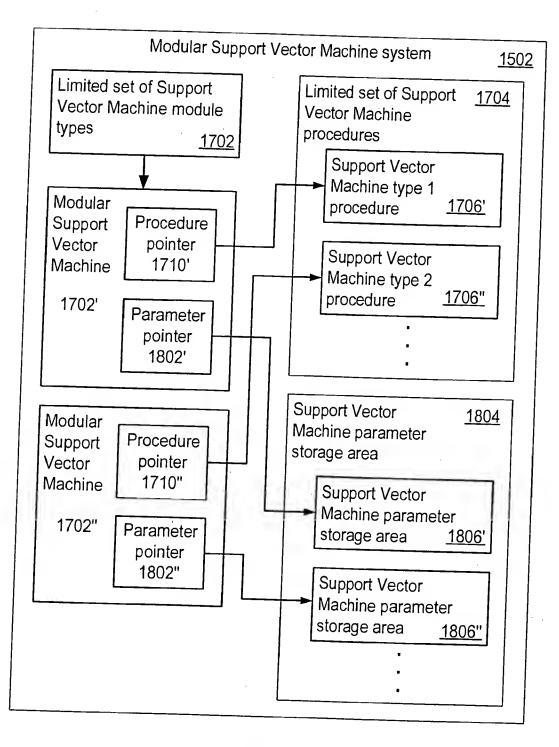


FIG. 21

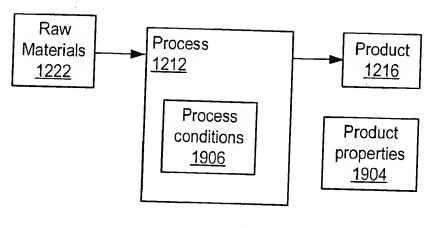


FIG. 22

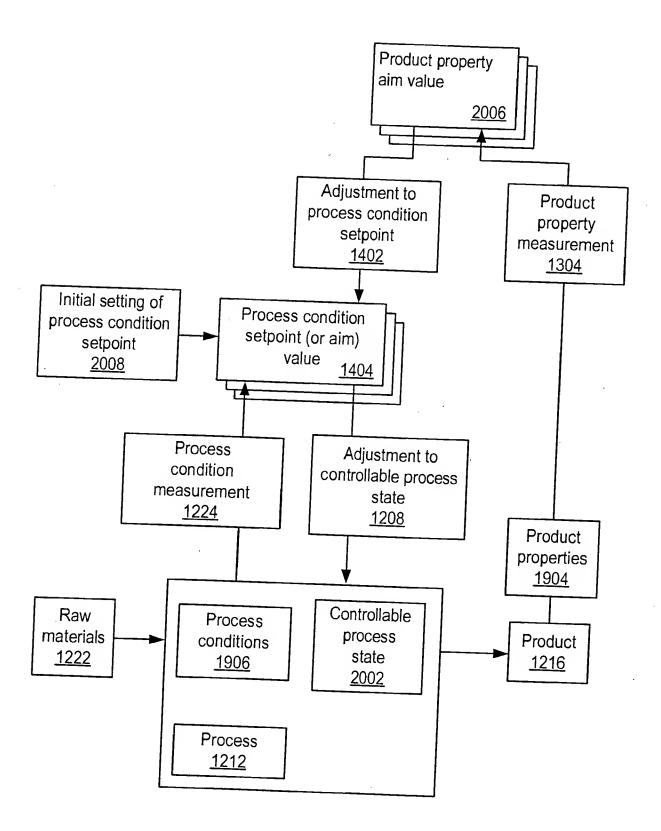
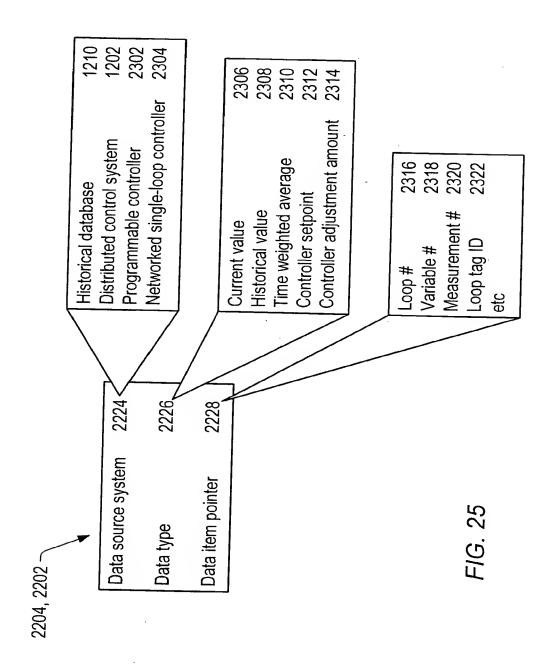
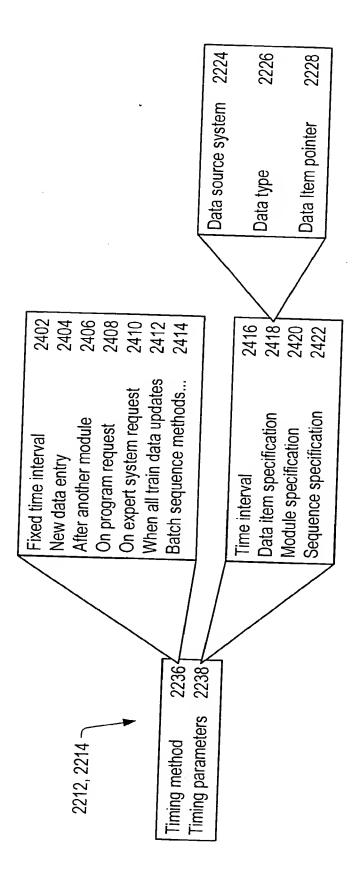


FIG. 23

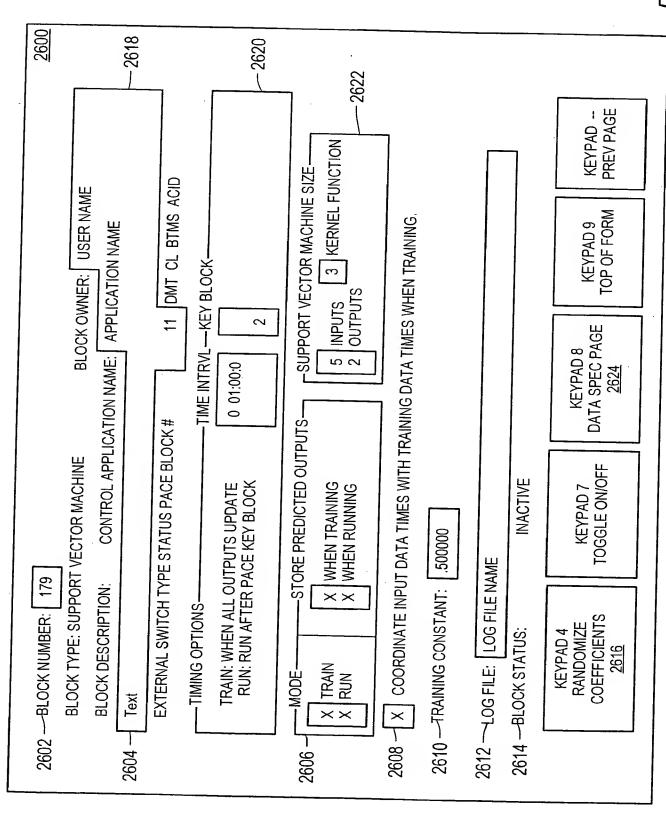
24	95	<u></u>						,	2240	2242	me	2244	6)
n 2224	2226	2228	2230	2232	2234		2236 2238		တ္ဆ	Input at	data ti	nput at	ata tim
Data source system		inter	ines				od neters		Use all current values	aining It data	g Indui	aining l t data a	input d
sonice	type	Data item pointer	Callable routines	Disk access	Network access		Timing method Timing parameters		currer	rrent tr th Inpu		rrent tra	aining
Data	Data type	Data	Callat	Disk a	Netwo		Timing Timing		Use all	Use current training Input data with Input data at	caniest training input data time	Use current training Input data with Input data at	latest training input data time
					7			/					
				\gg	\Rightarrow		\leftarrow						
			2202	2206	2210	2212	2214 2216 2218						
			Support Vector Machine model		-		Training data coordination Training method					FIG. 24	
				Support	Machine	0071							





F/G. 26

		Pneumatic single loop controller Electronic single loop controller Networked single loop controller Programmable loop controller Distributed control system Programmable logic controller	p controller controller p controller controller stem	2414 2516 2518 2520 2522 2522 2524
1202, 1406, 1408 Hardware Algorithm Parameters	re 2502 m 2504 ters 2506	Proportional (P) Proportional, Integral (PI) Propor, Integral, Derivative (PID) Internal model Adaptive Non-linear	re (PID)	2526 2528 2530 2532 2534 2534
Controller Timing means	Ø	Setpoint Proportional gain Integral gain Derivative gain		1404 2538 2540 2542 2542
Output signal	signal 2512 \	Output low limit Setpoint high limit Setpoint low limit		2546 2548 2550
		Timing method Timing parameters	2236 2238	
FIG. 27		Pressure signal 25 Voltage signal 25 Amperage signal 25 Digital value 25	2552 2554 2556 2558	



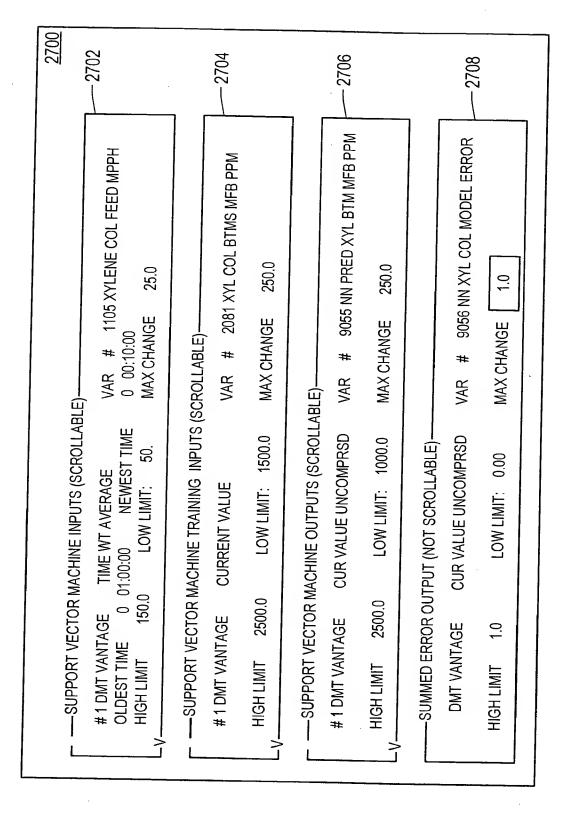


FIG. 29

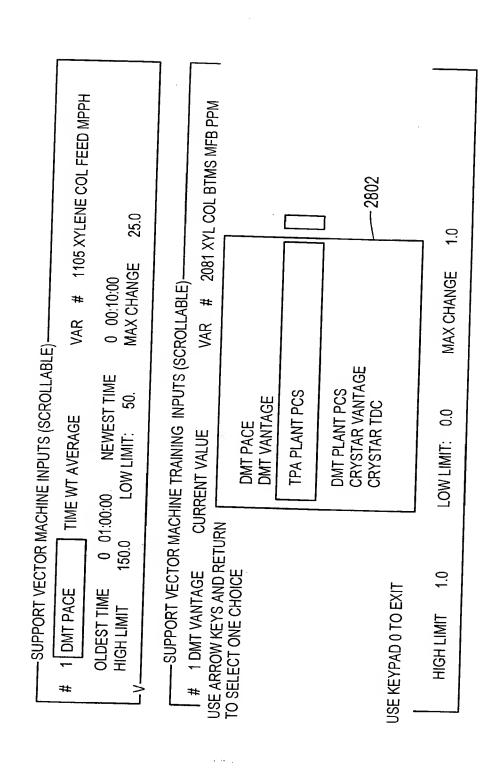
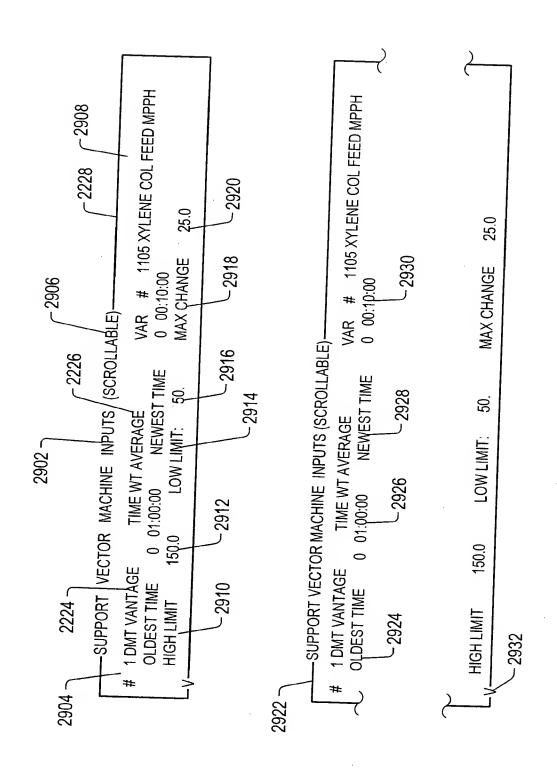
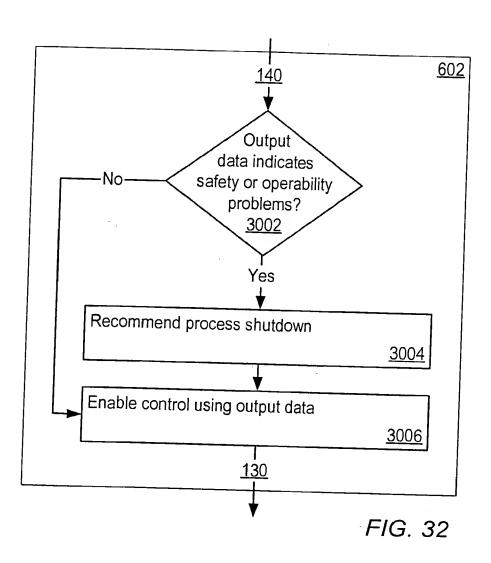


FIG. 30



F/G. 37



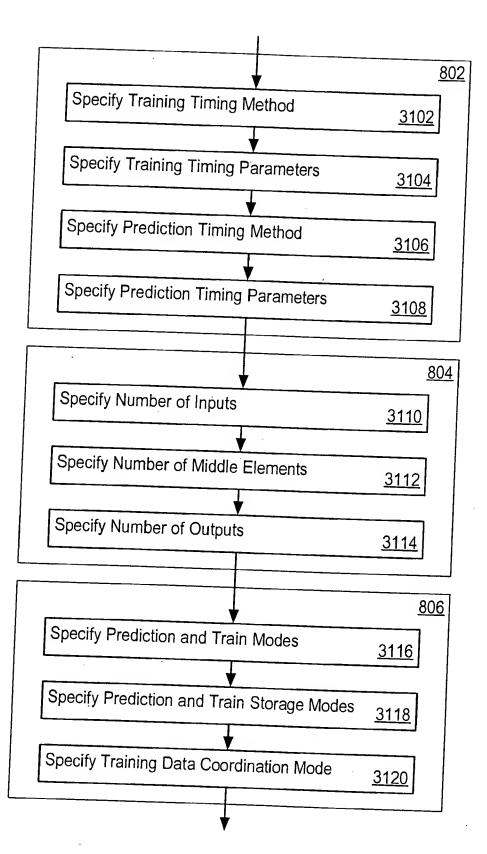


FIG. 33

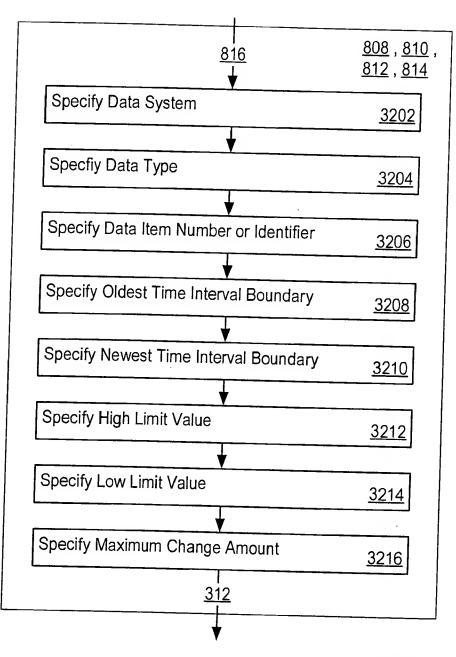


FIG. 34